

## TITLE OF THE INVENTION

### ACTUATOR

## BACKGROUND OF THE INVENTION

### 5           1. Field of the invention

The present invention generally relates to an actuator equipped with a unit that faces secured magnets and moves against the secured magnets, and more particularly, to an actuator to be incorporated into a device such as a mouse used in conjunction with a personal computer.

### 2. Description of the Related Art

Conventionally, an actuator has coils that face magnets arranged in a flat form, and moves the coils against the magnets by controlling current supplied to the coils. Such an actuator is expected to serve as a novel device that supplies information from computers to operators. Japanese Unexamined Patent Publication No. 2000-330688 discloses this type of actuator.

20           The above actuator can be incorporated into a mouse used in conjunction with a personal computer. Conventionally, a mouse is used simply as an input device that is operated by an operator to input data into a computer. However, with the above actuator incorporated into a mouse, various types of information can be supplied to an operator through the actuator being vibrated by transmitting various signals from the computer to the mouse. In such a case, the conventional mouse can serve as a man-machine interface.

30           In a case where the above actuator is incorporated into a conventional device such as a mouse, however, it is necessary to keep enough space for magnets and coils. As the number of components increases, the structure becomes more complicated, and the assembling becomes more difficult. Furthermore, the production costs increase as those problems arise.

## SUMMARY OF THE INVENTION

It is therefore an object of the present invention to provide an actuator in which the above disadvantage is eliminated.

5       A more specific object of the present invention is to provide an actuator that are small and easy to assemble, and can be smoothly incorporated into a conventional device.

10       The above objects of the present invention are achieved by an actuator comprising: magnets that are arranged in a flat form; coils that face the magnets; a moving member that is connected to the coils; a first holding member that holds the moving member in such a manner that the moving member can slide within a  
15       predetermined range; and a second holding member that holds the first holding member in such a manner that the first holding member can slide within a predetermined range in a direction perpendicular to the sliding direction of the moving member, the actuator  
20       moving the coils against the magnets.

      The above objects of the present invention are also achieved by an actuator comprising: coils that are arranged in a flat form; magnets that face the coils; a moving member that is connected to the magnets; a first  
25       holding member that holds the moving member in such a manner that the moving member can slide within a predetermined range; and a second holding member that holds the first holding member in such a manner that the first holding member can slide within a  
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member in such a manner that the moving member can slide within a predetermined range; and a second guide member that guides the first guide member in such a manner that the first guide member can slide within a  
5 predetermined range in a direction perpendicular to the sliding direction of the moving member, the actuator moving the coils against the magnets.

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10 arranged in a flat form; magnets that face the coils; a moving member that is connected to the magnets; a first guide member that guides the moving member in such a manner that the moving member can slide within a predetermined range; and a second guide member that  
15 guides the first guide member in such a manner that the first guide member can slide within a predetermined range in a direction perpendicular to the sliding direction of the moving member, the actuator moving the magnets against the coils.

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#### BRIEF DESCRIPTION OF THE DRAWINGS

Other objects, features and advantages of the present invention will become more apparent from the following detailed description when read in conjunction  
25 with the accompanying drawings, in which:

Fig. 1A illustrates the principles of the Fleming's left-hand rule;

Fig. 1B is a schematic view of magnets and coils employed in the present invention;

30 Figs. 2A through 2C illustrate the structure of Fig. 1B in greater detail;

Fig. 3 illustrates the relationship between the location of the coils in the X-direction and the Y-direction of Fig. 1B and thrust force;

35 Fig. 4 is a perspective view of an actuator of a first embodiment of the present invention;

Fig. 5A is a plan view of the actuator of the

first embodiment;

Fig. 5B is a front view of the actuator of the first embodiment;

Fig. 5C is a bottom view of the actuator of the first embodiment;

Fig. 6 illustrates the slider of the actuator of the first embodiment;

Fig. 7A is a perspective view of the slider of the actuator of the first embodiment;

Fig. 7B is an exploded perspective view of the slider of the actuator of the first embodiment;

Figs. 8A and 8B each illustrates an example structure that can be employed as the slider of the actuator of the first embodiment;

Fig. 9 illustrates a modification of the first embodiment;

Fig. 10 is a block diagram illustrating an example structure of the actuator of the first embodiment;

Figs. 11A and 11B illustrate an actuator of a second embodiment of the present invention;

Figs. 12A and 12B illustrate an actuator of a third embodiment of the present invention;

Figs. 13A and 13B illustrate an actuator of a fourth embodiment of the present invention;

Figs. 14A and 14B illustrate an actuator of a fifth embodiment of the present invention;

Figs. 15A and 15B illustrate an actuator of a sixth embodiment of the present invention;

Fig. 16 is a perspective view of an actuator of a seventh embodiment of the present invention;

Fig. 17A is a plan view of the actuator of the seventh embodiment;

Fig. 17B is a side view of the actuator of the seventh embodiment;

Fig. 17C is a section view of the actuator of the seventh embodiment;

Fig. 18A is a perspective view of an actuator of an eighth embodiment of the present invention;

Fig. 18B is a plan view of the actuator of the eighth embodiment;

5 Fig. 19A is a section view of the actuator of the eighth embodiment, taken along the line B-B of Fig. 18B;

10 Fig. 19B is a section view of the actuator of the eighth embodiment, taken along the line C-C of Fig. 18B;

Fig. 20A is a perspective view of an actuator of a ninth embodiment of the present invention;

Fig. 20B is a plan view of the actuator of the ninth embodiment;

15 Fig. 21 is a section view of the actuator of the ninth embodiment, taken along the line D-D of Fig. 20B;

Fig. 22 is an exploded perspective view of an actuator of a tenth embodiment of the present invention;

20 Figs. 23A through 23C illustrate an eleventh embodiment of the present invention, where the board to which the coils are secured is improved;

25 Figs. 24A through 24D illustrate a twelfth embodiment of the present invention, in which adverse influence from impact force and impact noise is reduced;

Figs. 25A and 25B illustrate an actuator of a thirteenth embodiment of the present invention equipped with a mechanism that stands by when not being used;

30 Figs. 26A and 26B illustrate an actuator of a fourteenth embodiment of the present invention that has a preferable structure for application to a device such as a mouse;

35 Figs. 27A through 27D illustrate a microrelay of a fifteenth embodiment of the present invention that has another preferable structure for application to a device such as a mouse;

Figs. 28A and 28B illustrate output conditions of the actuator of the fifteenth embodiment having the structure shown in Figs. 27A through 27D, with the moving piece being moved;

5 Fig. 29 illustrates a structure in which the coils are secured and the magnets are moved; and

Fig. 30 illustrates a structure in which electromagnets are employed as the magnets.

#### 10 DESCRIPTION OF THE PREFERRED EMBODIMENTS

The following is a description of embodiments of the present invention, with reference to the accompanying drawings.

First, the principles of the technique utilized  
15 in the embodiments of the present invention will be briefly described. Figs. 1A and 1B illustrate the relationship between coils and magnets. The present invention is based on the Fleming's left-hand rule.

Fig. 1A illustrates the Fleming's left-hand rule.  
20 As can be seen from Fig. 1A, coils 2 are located in the vicinity of the magnets 1. When current 3 flows in the direction of the white arrow, a thrust force 4 acting in the direction of the black arrow is caused in the coils 2 on the basis of the Fleming's left-hand rule.  
25 Fig. 1B schematically illustrates the structure of magnets and coils employed in the embodiments of the present invention. As can be seen from Fig. 1B, coils 2 are arranged over magnets 1 that are arranged in a flat form, with the N-poles and S-poles being  
30 alternately located. These coils 2 are secured to a moving mechanism (not shown). The current to be supplied to the coils 2 is controlled so that the coils 2 can be moved two-dimensionally in the X-Y plane by virtue of the thrust force shown in Fig. 1A. The  
35 present invention provides an actuator that utilizes this structure.

Figs. 2A through 2C illustrate the structure of

Fig. 1B in greater detail. Fig. 2A is a perspective view illustrating the relationship between the magnets 1 and the coils 2, Fig. 2B is a plan view of the same, and Fig. 2C is a bottom view of the same. In Figs. 2A  
5 through 2C, the magnets 1 are secured onto a bottom plate 12. The coils 2 face the flat surfaces of the magnets 1 that are arranged in a flat form, and move two-dimensionally over the magnets 1 (in-plane movement). In this embodiment, the bottom plate 12 has  
10 an opening 15 to detect movements of the coils 2.

The magnets 1 shown in Fig. 1B and Figs. 2A through 2C may be either permanent magnets or electromagnets. Also, the magnets 1 may be moved while the coils 2 are secured.

15 Fig. 3 illustrates the relationship between the location of the coils and the thrust force (load N) in the X-direction and the Y-direction in Fig. 1B. In Fig. 3, the location of the coils is represented by the abscissa axis, while the load N caused in the coils is  
20 represented by the ordinate axis. In this example, a current of 200 mA is applied to the coils, and magnets of 12000 Gauss are employed. In Fig. 1B, the position in which each of the coils 2 lies across an N-pole and an S-pole is the center position. The greatest load N  
25 is generated in this center position, and it has been found that sufficient load N can be generated in a position that is off the center position by  $\pm 5$  millimeters. In the following, further embodiments of the present invention will be described.

30 Fig. 4 and Figs. 5A through 5C illustrate an actuator that is a first embodiment of the present invention. Fig. 4 is a perspective view of this actuator, Fig. 5A is a plan view of the same, Fig. 5B is a front view of the same, and Fig. 5C is a bottom  
35 view of the same. This actuator is a component to be incorporated into a device such as a mouse.

In Fig. 4 and Figs. 5A through 5C, this actuator

is formed on the bottom plate 12. The magnets 1 arranged in a flat form are placed onto the bottom surface 12, with the magnetic poles being located alternately (see Figs. 2A through 2C). A supporting  
5 plate 10 is provided over the bottom plate 12 via spacers 11. A moving mechanism for moving the coils 2 two-dimensionally as described above is formed on the supporting plate 10.

A slider 20 only partially shown as the moving  
10 mechanism in Fig. 4 faces the upper surfaces of the magnets 1, as shown in Fig. 5B. A moving piece 5 protrudes from the upper surface of the slider 20. A front view and a side view of the slider 20 are shown in Fig. 6. In the side view, an enlarged view of a  
15 part of the slider 20 is shown. A circuit board 30 is embedded in the slider 20, and the coils 2 are secured to the board 30. The moving piece 5 is formed on the back of the slider 20.

Referring back to Fig. 4, the moving piece 5 is  
20 slidably held by a first holding member 6. A through hole is formed in the lower part of the moving piece 5, so that the moving piece 5 is engaged with a shaft 7 provided to the first holding member 6. This shaft 7 is secured to the inner surface of the ring-like first  
25 holding member 6. Accordingly, the moving piece 5 can slide in one direction while being held by the shaft 7 inside the first holding member 6.

The first holding member 6 is also slidably held  
by a second holding member 9. The second holding  
30 member 9 has a pair of shafts 8-1 and 8-2 that are arranged at a distance from each other. The first holding member 6 is slidably engaged with the shafts 8-1 and 8-2. A through hole is formed at either side of the first holding member 6, so that the first holding  
35 member 6 can be engaged with the shafts 8-1 and 8-2. Accordingly, the first holding member 6 slidably moves while being held by the shafts 8-1 and 8-2 inside the

second holding member 6.

In the above structure, the moving piece 5 slides in one direction inside the first holding member 6, and the first holding member 6 moves inside the second holding member 9 in a direction perpendicular to the moving direction of the moving piece 5. Accordingly, when a certain thrust force is applied to the slider 20 having the coils 2 connected thereto, the moving piece 5 can freely move in a two-dimensional plane. This actuator is incorporated into a device such as a mouse, so that an operator can touch the moving piece 5 with his/her finger and sense a thrust force generated in the actuator.

Figs. 7A and 7B and Figs. 8A and 8B illustrates example structures that can be employed as the slider 20. Fig. 7A is a perspective view of the slider 20, and Fig. 7B is an exploded view of the slider 20. The slider 20 has pins 22 for positioning the board 30. Openings 32 corresponding to the pins 22 are formed in the board 30. As can be seen from Fig. 7A, the pins 22 also define the location of the coils 22. With this structure, it is possible to position and secure the board 30 and the coils 2 to the slider 20 with high precision.

Further, positioning walls stand from the peripheral parts of the slider 20. Each of the walls has an engaging claw 25 that is tapered downward, as shown in the enlarged view indicated by a circle. Accordingly, when the board 30 is pressed downward, the engaging claw can surely catch the board 30.

Figs. 8A and 8B illustrate other example structures that can be employed as the slider 20 of the actuator. Fig. 8A shows a structure in which ribs 34 for positioning the coils 2 stand from the board 30. As can be seen from Fig. 8A, with the ribs 34, the coils 2 can be surely secured at the predetermined location on the board 30. Fig. 8B shows a structure in

which the coils 2 are integrally molded with the board 30 that is made of a resin material. In this structure, the coils 2 are embedded in the board 30, and thus are surely held and secured. Furthermore, there is no need  
5 to employ parts for securing the coils 2.

Fig. 9 illustrates a modification of the first embodiment. The actuator shown in Fig. 4 is a self-contained structure, with the magnets 1 being secured onto the bottom plate 12. However, since this actuator  
10 is to serve as one component, the same structure can be obtained by arranging the magnets 1 on a board to which this actuator is to be secured. In such a case, an incomplete actuator without the bottom plate 12 and the magnets 1 arranged on the bottom plate 12, which are  
15 included in the structure shown in Fig. 4, should be prepared as shown in Fig. 9.

Fig. 10 is a block diagram showing an example structure of this actuator. A unit such as a CPU provided to the board 30 serves as a control  
20 microcomputer unit 42 to control the current flowing into the coils of this actuator. The control microcomputer unit 42 is connected to an apparatus such as an external computer via an interface unit 41. Based on a signal supplied from the computer, the  
25 control microcomputer unit 42 supplies a drive signal to a motor driver unit 43. Upon receipt of the drive signal, the motor driver unit 43 adjusts the current to be supplied to an X-axis driver unit 44 and a Y-axis driver unit 45. Here, the X-axis driver unit 44 and  
30 the Y-axis driver unit 45 are equivalent to the coils 2 described above.

In a case where this actuator is incorporated into a mouse, it is necessary to detect the location of the coils 2. In such a case, a signal supplied from a  
35 sensor unit 46 such as a photodetector (PD) provided in the mouse is supplied to and utilized by the control microcomputer unit 42.

Figs. 11A and 11B illustrate an actuator that is a second embodiment of the present invention. Fig. 11A is a plan view of the actuator, and Fig. 11B is a front view of the same. It should be noted that the same components as those in the first embodiment are denoted by the same reference numerals as the corresponding ones in the first embodiment, and explanation of those components will be omitted. This also applies to the descriptions of embodiments that will follow.

10 This embodiment is characterized in that the shafts 8-1 and 8-2 of the second holding member 9 holding the first holding member 6 are replaced with a single shaft 18 that has a quadrangular section. The shaft 18 is secured to one inner side of the second holding member 9. Since the section of the shaft 18 is quadrangular, the first holding member 6 does not rotate on the shaft 18 even if the first holding member 6 is held only at an end. With the shaft 18, the first holding member 6 can be slidably cantilevered. As the number of shafts used in the second holding member 9 is reduced in this embodiment, the entire structure can be simplified, and the production costs can be reduced accordingly. Although being quadrangular in the example shown in Figs. 11A and 11B, the section of the shaft 18 may be triangular, pentagonal, or in any other suitable angular form.

Figs. 12A and 12B illustrate an actuator that is a third embodiment of the present invention. Fig. 12A is a plan view of the actuator, and Fig. 12B is an enlarged view of a first holding member 16 of the actuator. This embodiment is characterized in that the first holding member 16 is formed by performing bending or pressing on a sheet metal material. To form the first holding member 16 of this embodiment, the sheet metal material is bent and molded, and the shaft 7 is secured therein. Each of the standing parts that are to serve as side walls has a pair of openings 17-1 and

17-2 to be engaged with the shafts 8-1 and 8-2. As the first holding member 16 can be easily formed through metal plate processing, the production costs can be reduced.

5 Figs. 13A and 13B illustrate an actuator that is a fourth embodiment of the present invention. Fig. 13A is a plan view of the actuator, and Fig. 13B is a front view of the same. In this embodiment, the magnets 1 and the spacers 11 of the first embodiment are  
10 integrally molded using a magnetic material to form a base 19. As the magnets and the spacers are integrally formed in this embodiment, the number of components is reduced, and the production procedures can be simplified.

15 Figs. 14A and 14B illustrate an actuator that is a fifth embodiment of the present invention. Fig. 14A is a plan view of the actuator, and Fig. 14B is a front view of the same. This embodiment is characterized by coils 21 that are coated with a black coating. As the  
20 exterior of the coils 21 is black, it is possible to prevent diffused reflection. If this actuator is incorporated into a device such as a mouse, and is placed near a light-emitting device such as a LED, a decrease in detection sensitivity due to diffused  
25 reflection of the coils can be avoided.

Figs. 15A and 15B illustrate an actuator that is a sixth embodiment of the present invention. Fig. 15A is a plan view of the actuator, and Fig. 15B is a front view of the same. This embodiment is characterized in  
30 that the coils 2 are insert-molded with and secured to the resin board 30 to be secured to the slider 20. Through the insert-molding, the step of incorporating the coils 2 into the board 30 can be omitted, and the coils 2 can be surely secured to the board 30.

35 Fig. 16 and Figs. 17A through 17C illustrate an actuator that is a seventh embodiment of the present invention. Fig. 16 is a perspective view of the

actuator. Fig. 17A is a plan view of the actuator, Fig. 17B is a side view of the same, and Fig. 17C is a section view of the same, taken along the line A-A of Fig. 17A. This embodiment is characterized in that the first holding member 6 is molded in such a manner as to be in contact only with the lower sides of the pair of shafts 8-1 and 8-2 of the second holding member 9. This feature of the first holding member 6 is more clearly shown in Figs. 7A and 7C.

10       As the first holding member 6 does not need to have holes to be engaged with the shafts 8-1 and 8-2 in this embodiment, the entire structure can be simplified. Also, as the second holding member 9 can be simply placed onto the first holding member 6, the production  
15       procedures can be simplified.

      Figs. 18A through 19B illustrate an actuator that is a ninth embodiment of the present invention. Fig. 18A is a perspective view of the actuator, and Fig. 18B is a plan view of the same. Fig. 19A is a section view of the actuator, taken along the line B-B of Fig. 18B. Fig. 19B is a section view of the actuator, taken along the line C-C of Fig. 18B.

      In the foregoing embodiments, the first holding member 6 includes the shaft 7, and the second holding member 9 includes the shafts 8-1 and 8-2 or the shaft 18. However, this embodiment is a structure that does not require any shaft. As can be seen from Figs. 18A and 18B, a moving piece 50 is guided by a guide member 56 that is equivalent to the first holding member 6.  
25       This guide member 56 is guided along guide paths 65 formed by an upper guide plate 60 and a lower guide plate 62. Accordingly, the guide member 56 is equivalent to the first guide member in claims, and the upper guide plate 60 and the lower guide plate 62 are  
30       equivalent to the second guide member in claims.  
35       The moving piece 50 of this embodiment is guided along the inner wall of the guide member 56 that is

formed in a rectangular shape. The slider 20 to which the coils 2 are secured is connected to the lower end of the moving piece 50. The coils 2 face the magnets 1 below. When a predetermined current is not supplied to the coils 2, the coils 2 are placed directly onto the magnets 1. When the current is supplied to the coils 2, the coils 2 are lifted off the magnets 1 by virtue of magnetic repulsion caused between the coils 2 and the magnets 1. Thus, the coils 2 can be moved against the magnets 1.

As can be seen from Fig. 19A, the guide member 56 has inner walls 57 that have very small areas so as to reduce friction with the moving piece 50. As shown in Fig. 19B, both end parts 58 of the guide member 56 each has a step-like shape. Each of the end parts 58 is inserted into each corresponding guide path 65 formed by the upper guide plate 60 and the lower guide plate 62. As shown in the enlarged view indicated by a circle, the upper and lower surfaces of each end part 58, i.e., the surfaces to face the upper guide plate 60 and the lower guide plate, each has a protrusion 59. Accordingly, the friction is minimized when the guide member 56 moves along the guide paths 65. Each protrusion 59 extends in the longitudinal direction and thus serves as a rail. Although the protrusions 59 are formed on the end parts 58 in this embodiment, it is also possible to provide the protrusions 59 on the upper guide plate 60 and the lower guide plate 62, instead of on the end parts 58. Also, each protrusion 59 is not limited to the rail type, but the same effects can be achieved with a structure having hemispheric protrusions that are scatteringly formed thereon. As the actuator of this embodiment does not employ a shaft, the entire structure can be simplified, and the work efficiency in assembling the actuator can be increased.

Figs. 20A and 20B and Fig. 21 illustrate an

actuator that is a ninth embodiment of the present invention. Fig. 20A is a perspective view of the actuator, and Fig. 20B is a plan view of the same. Fig. 21 is a section view of the actuator, taken along the line D-D of Fig. 20B. This embodiment is an improved modification of the eighth embodiment. The moving piece 50 has an engaging tongue 52 at either side. Each engaging tongue 52 is engaged with the guide member 56 so as to prevent the moving piece 50 from coming off the guide member 56.

Each of the engaging tongues 52 is a tongue-like part that protrudes from each corresponding side wall of the moving piece 50 and is tapered outward, as can be seen from Fig. 21. The engaging tongues 52 can be elastically deformed. At the time of assembling the actuator, the guide member 56 is positioned to the moving piece 50 and is pushed toward the guide member 56. By doing so, the engaging tongues 52 are elastically deformed. After sliding through the guide member 56, the engaging tongues 52 are restored to the original state, and are engaged with the guide member 56, as shown in Fig. 21. As the engaging tongues are located on the step-like parts of the guide member 56 and serve to prevent the guide member 56 from coming off, assembling the actuator can be efficiently conducted.

As the engaging tongues 52 are engaged with the guide member 56, the moving piece 50 as well as the slider 20 and the coils 2 located below the moving piece 50 and connected to the moving piece 50 can also be securely held. Here, it is more preferable that the engaging tongues 52 can move smoothly within the guide member 56. Therefore, a rail-like protrusion 54 is formed at the bottom of each engaging tongue 52 in this embodiment. The protrusions 54 may be formed on the guide member 56, instead of on the engaging tongues 52.

Fig. 22 is an exploded perspective view of an

actuator that is a tenth embodiment of the present invention. This embodiment is also a modification of the eighth and ninth embodiments, and is characterized in that the protrusions on the end parts 58 of the  
5 guide member 56 are replaced with concave parts. In this embodiment, concave parts 67 are scatteringly formed on the upper surfaces of the end parts 58. With the concave parts 67, it is also possible to achieve a structure in which the guide member 56 smoothly moves  
10 and reduces friction. It is more preferable to form the concave parts 67 also on the lower surfaces of the end parts 58.

It is also possible to form concave parts 67 on the lower surface of the upper guide plate 60 and the  
15 upper surface of the lower guide plate 62, instead of on the upper and lower surfaces of the end parts 58. Further, it is also possible to form the concave parts 67 on the lower surface of the upper guide plate 60 and the upper surface of the lower guide plate 62 as well  
20 as on the upper and lower surfaces of the end parts 58.

Figs. 23A through 23C illustrate an eleventh embodiment of the present invention, in which the board that secures the coils 2 is improved. Figs. 23A through 23C each shows an example of a board that can  
25 be employed in the actuator of this embodiment.

Fig. 23A illustrates a structure in which a board 70 is integrally formed with a slider. This is a simple structure in which the coils 2 are simply bonded to the board 70. Accordingly, the production costs can  
30 be reduced, and work efficiency in the production procedures can be increased. Fig. 23B illustrates a preferable structure in which coils are bonded to a board. In this structure, the coils 2 are bonded to a board 71, and wiring is arranged in the board 71. With  
35 this structure, the production costs can be reduced, and work efficiency in the production procedures can be increased. Fig. 23C illustrates another preferable

structure in which the coils 2 are bonded to a board 72, and ribs 73 for securing the coils 2 are also inserted into holes formed in the board 72. With this structure, the coils 2 are surely secured. This embodiment and  
5 the embodiments that will be described later can be applied not only to actuators without a shaft, such as the actuator of the eighth embodiment, but also to actuators with shafts, such as the actuator of the first embodiment.

10 Figs. 24A through 24D illustrate a twelfth embodiment of the present invention, in which impact force and impact noise caused when the moving piece reaches an end of the slidable range can be reduced. Figs. 24A through 24D each shows a specific example of  
15 such a structure. This embodiment employs the slidable moving piece 50, the guide member 56, the upper guide plate 60, and the lower guide plate 62 of the eighth embodiment.

Fig. 24A shows a structure in which protrusions  
20 75 are provided so as to reduce the impact areas in the direction of guiding the moving piece 50 and in the direction of guiding the guide member 56. As the protrusions 75 are formed when the moving piece 50 and the guide member 56 are molded, this structure can be  
25 easily produced. Here, it is preferable to employ parts that can be elastically deformed at the impact points. Fig. 24B shows a structure in which plate springs 76 are employed. Fig. 24C shows a structure in which coil springs 77 are employed. Fig. 24D shows a  
30 structure in which impact absorption parts 78 made of rubber or sponge are employed. With any of these structures, impact force caused by a collision of the moving piece 50 can be reduced, and impact noise can be eliminated.

35 Figs. 25A and 25B illustrate an actuator that is a thirteenth embodiment of the present invention. This actuator is equipped with a mechanism that stands by

when not being used. Fig. 25A is a plan view of the actuator that is being used. Fig. 25B is a plan view of the actuator that is not being used and stands by. This embodiment can also be applied to an actuator  
5 without a shaft, such as the actuator of the eighth embodiment.

This actuator includes a stick-like member 80 that can rotate about a rotation shaft 82. The stick-like member 80 is retracted to such a position that is  
10 not obstructive to the operation when the actuator is being used, as shown in Fig. 25A. When the actuator is not being used, on the other hand, the stick-like member 80 is rotated about the rotation shaft 82, so that the stick-like member 80 is brought into contact  
15 with the moving piece 50 and holds the upper right end of the moving piece 50. With the actuator having the stand-by mechanism of this embodiment, the moving piece 50 and the slider connected to the moving piece 50 can be stably held in a predetermined position.

20 Figs. 26A and 26B illustrate an actuator that is a fourteenth embodiment of the present invention. This actuator has a structure that can be suitably applied to a device such as a mouse. Fig. 26A is a vertical section view of this actuator, and Fig. 26B is a bottom  
25 view of this actuator. Since this actuator is to be incorporated into a device such as a mouse, a LED 90 is provided for detecting the locations of the moving piece 50 and the coils 2. In a case where this actuator is incorporated into a mouse, light emitted  
30 from the LED 90 through the opening 15 is detected by a photodetector (PD) 95 that is located outside the actuator.

If the light emitted from the LED 90 is diffusedly reflected by the surfaces of the magnets 1,  
35 the detection accuracy of the PD 95 decreases. To avoid the diffused reflection, the side surfaces of the magnets 1 upon which the light emitted from the LED 90

impinges are coated with a black coating in this embodiment. An epoxy resin coating containing a black colorant is applied to the side surfaces of the magnets 1. It is more preferable to apply the black coating to the coils 2 as well.

Figs. 27A through 27D illustrate a microrelay of a fifteenth embodiment of the present invention. This microrelay is equipped with another structure that is suitable for a device such as a mouse. In Figs. 27A through 27D, the coils and the parts surrounding the coils are shown. The fourteenth embodiment shown in Figs. 26A and 26B employs the LED 90 and the PD 95 for detecting the locations of the moving piece 50 and the coils 2. In this embodiment, on the other hand, Hall devices that are magnetoelectric conversion devices are employed for detecting the locations of the moving piece 50 and the coils 2.

Fig. 27A is an enlarged view of the slider 20 seen from the coils 2. Fig. 27B is a right side view of the slider 20. Fig. 27C is a back view of the slider 20. Fig. 27D is a perspective view of the slider 20. As can be seen from Fig. 27A, four Hall devices 96 through 99 are arranged along the four coils 2. The Hall devices 96 and 98 are arranged on the line extending in the longitudinal direction of the slider 20. The Hall devices 97 and 99 are arranged on the line perpendicular to the longitudinal-direction line. In other words, the Hall devices 96 through 99 are arranged in the moving directions of the moving piece 50.

Although not shown in Figs. 27A through 27D, the coils 2 face the magnets 1, which is the same arrangement as that in the foregoing embodiments. When the slider 20 of this structure is moved against the magnets 1, the Hall devices 96 through 99 can detect the voltage from the movement. Accordingly, like the case of the fourteenth embodiment, the structure of

this embodiment can be suitably incorporated into a device such as a mouse, as the locations of the moving piece 50 and the coils 2 can be accurately detected.

5 Figs. 28A and 28B illustrate the output conditions in cases where the moving piece 50 of the actuator of the fifteenth embodiment shown in Figs. 27A through 27D is moved. Fig. 28A shows the output conditions in a case where the moving piece 50 is moved in the X-direction (i.e., in the direction of the Hall devices 97 and 99). Fig. 28B shows the output conditions in a case where the moving piece 50 is moved in the Y-direction (i.e., in the direction of the Hall devices 96 and 98). As can be seen from these drawings, the Hall devices can efficiently detect the locations of the moving piece 50 and the coils 2. Here, the Hall devices may be replaced with magneto-resistive devices.

15 Figs. 29 and 30 illustrate the magnets 1 and the coils 2 that are commonly employed in the actuators of the foregoing embodiments. The magnets 1 are secured while the coils 2 are moved in the foregoing embodiments. However, the coils 2 may be secured while the magnets 1 are moved, as shown in Fig. 29. In the structure shown in Fig. 29, the slider and the moving piece are connected to the magnets 1.

25 The magnets 1 employed in the foregoing embodiments are permanent magnets produced through sintering or the like. Instead, electromagnets 100 that are formed by winding coils may be employed as the magnets 1 of an actuator of the present invention, as shown in Fig. 30. The electromagnets 100 are advantageous in generating no magnetic force when the actuator is not being used.

35 In each of the foregoing embodiments, the slider of the actuator is driven by supplying current to the coils, i.e., the actuator is passively driven upon receipt of a signal from an apparatus such as a computer. However, application of the actuator of the

present invention is not limited to such an operation.  
An operator touches and moves the moving piece with  
his/her finger, so that current is generated in the  
coils by virtue of electromagnetic induction caused by  
5 the relative movement between the coils and the magnets  
facing the coils. With the current, the actuator can  
be used as an instruction input device for a computer.  
In this aspect, the actuator of the present invention  
is a novel actuator that can operate both passively and  
10 actively.

Also, the actuator of the present invention may  
be incorporated not only into a mouse, but also into  
other devices such as a vehicle, so that the flow of  
information, which is conventionally one-directional,  
15 can be two-directional or interactive.

Although a few preferred embodiments of the  
present invention have been shown and described, it  
would be appreciated by those skilled in the art that  
changes may be made in these embodiments without  
20 departing from the principles and spirit of the  
invention, the scope of which is defined in the claims  
and their equivalents.